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((ACLM/learn AND ACLM/"rotational speed") AND (SPEC/"ai" OR SPEC/neural?)) AND SPEC/shift?): 0 patents.

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Dialog level 05.12.03D
Last logoff: 10oct06 14:46:27
Logon file405 14oct06 20:18:49

***** ANNOUNCEMENTS *****

NEW FILES RELEASED

***Verdict Market Research (File 769)
***EMCare (File 45)
***Trademarkscan - South Korea (File 655)
***Regulatory Affairs Journals (File 183)
***Index Chemicus (File 302)
***Inspec (File 202)

RESUMED UPDATING

***File 141, Reader's Guide Abstracts

RELOADS COMPLETED

***File 11, PsycInfo
***File 531, American Business Directory
*** The 2005 reload of the CLAIMS files (Files 340, 341, 942
is now available online.

DATABASES REMOVED

***File 196, FINDEX
***File 468, Public Opinion Online (POLL)

Information:

1. Announcements (new files, reloads, etc.)
2. Database, Rates, & Command Descriptions
3. Help in Choosing Databases for Your Topic
4. Customer Services (telephone assistance, training, sem
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Connections:

6. DIALOG(R) Document Delivery
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14oct06 20:19:01 User264717 Session D502.1
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$0.05  Estimated cost this search
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SYSTEM:OS - DIALOG OneSearch

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S PD<=030117 AND SHIFT? AND (ROTATI? (2N) SPEED?) AND (LEARN
>>>One or more prefixes are unsupported
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T S2/3, KWIC/1

2/3, KWIC/1 (Item 1 from file: 95)

DIALOG(R) File 95:TEME-Technology & Management
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01289694 E99030200304

Influence of motion signals on the perceived position of sp
(Einfluss der Bewegungssignale auf die wahrgenommene Position
raeumlichen Musters)

Nishida, S; Johnston, A

NTT Kanagawa, J; Univ. College London, GB

Nature, v397, n6720, pp610-612, 1999

Document type: journal article Language: English

Record type: Abstract

ISSN: 0028-0836

1999

ABSTRACT:

...the motion aftereffect (MAE). It is thought that the MAE
accompanid by a shift in a spatial position of the pattern
providing psychophysical evidence for the dissociation of th
processing of motion and position that complements anatomica
physiological evidence of functional specialization in...

...is measured of a static windmill pattern after adaption t
and a gradual shift is found in orientation in the directi
illosity rotation, though at a rate much lower than the appa
speed. The orientation shift, which started to decline w
seconds, could persist longer than the MAE, and...
?

4/3, KWIC/1 (Item 1 from file: 8)
DIALOG(R)File 8:Ei Compendex(R)
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07537845 E.I. No: EIP05319278118

Title: Autonomous mobile robot control algorithm based on fuzzy behaviors in unknown environments

Author: Li, Shou-Tao; Li, Yuan-Chun
Corporate Source: College of Communication Engineering Jilin University Changchun 130022, China
Source: Jilin Daxue Xuebao (Gongxueban)/Journal of Jilin University (Engineering and Technology Edition) v 35 n 4 July 2005. p 3
Publication Year: 2005
CODEN: JDXGAH ISSN: 1671-5497
Language: Chinese

...Abstract: achieved by fuzzy reasoning scheme, and high behaviors were composed of these primitive behaviors. Neural networks were used to select and fuse different behaviors like a person's motion speed and rotational velocity of the mobile robot can change smoothly, because the sharp shift of different behaviors can exacerbate the absolute position errors. The feasibility of the design...

Descriptors: *Mobile robots; Algorithms; Fuzzy control; Navigation; Radio navigation

4/3, KWIC/2 (Item 2 from file: 8)
DIALOG(R)File 8:Ei Compendex(R)
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07097322 E.I. No: EIP04458446543

Title: Neuro/fuzzy behavior-based control of a mobile robot in unknown environments

Author: Li, Shou-Tao; Li, Yuan-Chun
Corporate Source: Dept. of Contr. Sci. and Engineering Jilin University ChangChun, 130025, China
Conference Title: Proceedings of 2004 International Conference on Learning and Cybernetics
Conference Location: Shanghai, China Conference Date: 2004-08-21
E.I. Conference No.: 63733
Source: Proceedings of 2004 International Conference on Learning and Cybernetics

and Cybernetics Proceedings of 2004 International Conference on Learning and Cybernetics v 2 2004. (IEEE cat n 04EX826)

Publication Year: 2004

ISBN: 0780384032

Language: English

...Abstract: discussed in our case. These elementary behaviors are achieved by means of fuzzy reasoning scheme. Neural networks select different behaviors so that the motion speed and velocity of the mobile robot are changed smoothly. The sharp difference behaviors will exacerbate the absolute position error. An explanation of the algorithm is...

Descriptors: *Mobile robots; Fuzzy control; Neural networks; Decision making; Problem solving; Genetic algorithms; Mathematics; Computer simulation